LISTING OF THE CLAIMS:

The listing of claims will replace all prior versions, and listings, of claims in the application.

Listing of the Claims:

1-11. (Canceled).

12. (Previously Presented) A method for determining an accident risk of a first object with at least one second object, comprising: determining the accident risk as a function of a collision probability and a hazard probability of the at least one second object in a predefined region, and determining the collision probability and the hazard probability as a function of motions of the first and at least one second object.

13. (Previously Presented) The method according to Claim 12, wherein an object class of the first and at least one second object are taken into account in determining the collision probability and the hazard probability.

14. (Previously Presented) The method according to Claim 12, wherein the motion and the object class of the at least one second object are determined by way of a sensor suite, and the motion and the object class of the first object are retrieved from at least one data source.

15. (Previously Presented) The method according to Claim 13, wherein the motion and the object class of the at least one second object are determined by way of a sensor suite, and the motion and the object class of the first object are retrieved from at least one data source.

16. (Previously Presented) The method according to Claim 12, wherein the motion of the first object is defined by at least one current position and its velocity.

17. (Previously Presented) The method according to Claim 13, wherein the motion of the first object is defined by at least one current position and its velocity.

18. (Previously Presented) The method according to Claim 12, wherein the motion of the at least one second object is defined by at least one current position.

19. (Previously Presented) The method according to Claim 13, wherein the motion of the at least one second object is defined by at least one current position.

20. (Previously Presented) The method according to Claim 14, wherein the motion of the at least one second object is defined by at least one current position.

21. (Previously Presented) The method according to Claim 16, wherein the motion of the at least one second object is defined by at least one current position.

22. (Previously Presented) The method according to Claim 16, wherein the motion of the first object is additionally determined by way of at least one of its first longitudinal acceleration, first transverse acceleration, a first rotation angle and a first steering angle.

23. (Previously Presented) The method according to Claim 18, wherein the motion of the at least one second object is determined by at least one of its velocity relative to the first object, a second longitudinal acceleration, a second transverse acceleration and a second rotation angle.

24. (Previously Presented) The method according to Claim 22, wherein at least one of environmental influences and a respective driving behavior are taken into account in determining the respective motion.

25. (Previously Presented) The method according to Claim 23, wherein at least one of environmental influences and a respective driving behavior are taken into account in determining the respective motion.

26. (Previously Presented) The method according to Claim 12, wherein at least one of an indication and at least one signal to an actuator suite are generated as a function of the accident risk.

27-28. (Canceled).

29. (Previously Presented) The method according to Claim 12, wherein an object class of the first and at least one second object are taken into account in determining the collision probability and the hazard probability, wherein the motion and the object class of the at least one second object are determined by way of a sensor suite, and the motion and the object

class of the first object are retrieved from at least one data source, wherein the motion of the first object is defined by at least one current position and its velocity, wherein the motion of the at least one second object is defined by at least one current position.

30. (Previously Presented) The method according to Claim 29, wherein the motion of the first object is additionally determined by way of at least one of its first longitudinal acceleration, first transverse acceleration, a first rotation angle and a first steering angle, and wherein the motion of the at least one second object is determined by at least one of its velocity relative to the first object, a second longitudinal acceleration, a second transverse acceleration and a second rotation angle.

31. (Previously Presented) The method according to Claim 29, wherein at least one of environmental influences and a respective driving behavior are taken into account in determining the respective motion, and wherein at least one of an indication and at least one signal to an actuator suite are generated as a function of the accident risk.